

Title (en)
MECHANICAL TELEOPERATED DEVICE FOR REMOTE MANIPULATION

Title (de)
FERNGESTEUERTE MECHANISCHE VORRICHTUNG ZUR FERNMANIPULATION

Title (fr)
DISPOSITIF MÉCANIQUE TÉLÉCOMMANDÉ POUR MANIPULATION À DISTANCE

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Application
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Abstract (en)
[origin: WO2013014621A2] There is described a mechanical teleoperated device (5a, 5b) for remote manipulation comprising: a slave unit (10) having a number of slave links (11, 12, 13, 14) interconnected by a plurality of slave joints (16, 17, 18, 19); ii) an end-effector (40) connected to the distal end of the slave unit (10); a master unit (20) having a corresponding number of master links (21, 22, 23, 24) interconnected by a plurality of master joints (26, 27, 28, 29); and a handle (30) connected to the distal end of the master unit (20) for operating the mechanical teleoperated device. The device further comprises first mechanical transmission means (61, 62, 63, 64) arranged to kinematically connect the slave unit (10) with the master unit (20) such that the movement applied on each master joint (26, 27, 28, 29) of the master unit (20) is reproduced by the corresponding slave joint (16, 17, 18, 19) of the slave unit (10), second mechanical transmission means (65, 66, 67) arranged to kinematically connect the end-effector (40) with the handle (30) such that the movements applied on the handle (30) are reproduced by the end-effector (40), and mechanical constraint means (32) configured to ensure that one master link (24) of said master unit (20) is guided along its longitudinal axis (?1) so that the corresponding slave link (14) of the slave unit (10) always translates along a virtual axis (?4) parallel to the longitudinal axis of said guided master link (24) in the vicinity of the remote manipulation when the mechanical teleoperated device (5 a, 5b) is operated. The mechanical teleoperated device (5 a, 5b) according to the invention is configured to enable the guided master link (24) of the master unit (20) to rotate about its longitudinal axis (?1), and about a second and a third axis (?2, ?3), wherein the longitudinal axis (??) of the guided master link (24) and the second and third axes (?2, ?3) always intersect each other at a stationary single point (32') independently of the orientation of said guided master link (24) to enable the corresponding slave link (14) of the slave unit (10) to rotate about its longitudinal axis (?4), and about a fifth and a sixth virtual axis (?5, ?6) which are parallel respectively to said second and third axes (?2, ?3), wherein the longitudinal axis (?4) of said corresponding slave link (14) and the fifth and sixth virtual axes (?5, ?6) always intersect each other at a virtual stationary single point (50) in the vicinity of the remote manipulation.

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See references of WO 2013014621A2

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